AMENDMENTS TO THE CLAIMS

The following listing of claims will replace all prior versions of claims in the application:

1-36. (Canceled)

37. (Currently Amended) A method, comprising:

outputting a signal associated with a first haptic force associated with a first force profile, the first force profile being associated with a graphical representation for display within a graphical user interface, the graphical representation being illustrative of a force versus time characteristic of the first force profile;

receiving a control signal associated with a movement by a user of a control point of the graphical representation, the movement of the control point operative to change the first force profile to a second force profile; and

outputting a signal associated with a second haptic force, the second haptic force being based on the second force profile and being different from the first haptic force.

38. (Currently Amended) The method of claim 37, wherein at least one actuator is configured to output ~~at least~~ one of either the first haptic force ~~and~~ or the second haptic force as a function of displacement of a manipulandum.

39. (Previously Presented) The method of claim 37, wherein the movement of the control point is operative to modify a stiffness associated with the first force profile to obtain the second force profile.

40. (Currently Amended) The method of claim 37, wherein the control point ~~being~~ is a first ~~control point from~~ of a plurality of control points, and wherein the movement of at least the first control point and a second control point ~~from~~ of the plurality of control points ~~being~~ is operative to modify a slope associated with the first force profile.

41. (Previously Presented) The method of claim 37, wherein the movement of the control point is operative to modify a damping parameter associated with the first force profile.

42. (Currently Amended) The method of claim 37, wherein the control point ~~being from~~ is one of a plurality of control points, and wherein each control point ~~from~~ of the plurality of control points is independently moveable.

43. (Previously Presented) The method of claim 37, wherein the second force profile is symmetrical about a midpoint independent of the movement of the control point.

44-56. (Canceled)

57. (Currently Amended) A processor-readable medium comprising code representing instructions to cause a processor to:

output a signal associated with a first haptic force associated with a first force profile, the first force profile being associated with a graphical representation for display within a graphical user interface, the graphical representation being illustrative of a force versus time characteristic of the first force profile;

receive a control signal associated with a movement by a user of a control point of the graphical representation, the movement of the control point operative to change the first force profile to a second force profile; and

output a signal associated with a second haptic force, the second haptic force being based on the second force profile and being different from the first haptic force.

58. (Canceled)

59. (New) An apparatus, comprising:

means for outputting a signal associated with a first haptic force associated with a first force profile, the first force profile being associated with a graphical representation for display within a graphical user interface, the graphical representation being illustrative of a force versus time characteristic of the first force profile;

means for receiving a control signal associated with a movement by a user of a control point of the graphical representation, the movement of the control point operative to change the first force profile to a second force profile; and

means for outputting a signal associated with a second haptic force, the second haptic force being based on the second force profile and being different from the first haptic force.

60. (New) A method, comprising:

retrieving a first force profile associated with a first haptic force, the first force profile being associated with a graphical representation for display within a graphical user interface, the graphical representation being illustrative of a force versus time characteristic of the first force profile;

receiving a control signal associated with a movement by a user of a control point of the graphical representation, the movement of the control point operative to change the first force profile to a second force profile; and

storing the second force profile associated with a second haptic force, the second haptic force being based on the second force profile and being different from the first haptic force.

61. (New) The method of claim 60, wherein at least one actuator is configured to output one of either the first haptic force or the second haptic force as a function of displacement of a manipulandum.

62. (New) The method of claim 60, wherein the movement of the control point is operative to modify a stiffness associated with the first force profile to obtain the second force profile.

63. (New) The method of claim 60, wherein the control point is a first of a plurality of control points, and wherein the movement of at least the first control point and a second control point of the plurality of control points is operative to modify a slope associated with the first force profile.

64. (New) The method of claim 60, wherein the movement of the control point is operative to modify a damping parameter associated with the first force profile.

65. (New) The method of claim 60, wherein the control point is one of a plurality of control points, and wherein each control point of the plurality of control points is independently moveable.

66. (New) The method of claim 60, wherein the second force profile is symmetrical about a midpoint independent of the movement of the control point.

67. (New) A processor-readable medium comprising code representing instructions to cause a processor to:

retrieve a first force profile associated with a first haptic force, the first force profile being associated with a graphical representation for display within a graphical user interface, the graphical representation being illustrative of a force versus time characteristic of the first force profile;

receive a control signal associated with a movement by a user of a control point of the graphical representation, the movement of the control point operative to change the first force profile to a second force profile; and

store the second force profile associated with a second haptic force, the second haptic force being based on the second force profile and being different from the first haptic force.

68. (New) An apparatus, comprising:

means for retrieving a first force profile associated with a first haptic force, the first force profile being associated with a graphical representation for display within a graphical user interface, the graphical representation being illustrative of a force versus time characteristic of the first force profile;

means for receiving a control signal associated with a movement by a user of a control point of the graphical representation, the movement of the control point operative to change the first force profile to a second force profile; and

means for storing the second force profile associated with a second haptic force, the second haptic force being based on the second force profile and being different from the first haptic force.

69. (New) A method, comprising:

outputting a signal associated with a first haptic force associated with a first force profile, the first force profile being associated with a graphical representation for display within a graphical user interface, the graphical representation being illustrative of a force versus any one of a position, velocity or acceleration characteristic of the first force profile;

receiving a control signal associated with a movement by a user of a control point of the graphical representation, the movement of the control point operative to change the first force profile to a second force profile; and

outputting a signal associated with a second haptic force, the second haptic force being based on the second force profile and being different from the first haptic force.

70. (New) The method of claim 69, wherein at least one actuator is configured to output one of either the first haptic force or the second haptic force as a function of displacement of a manipulandum.

71. (New) The method of claim 69, wherein the movement of the control point is operative to modify a stiffness associated with the first force profile to obtain the second force profile.

72. (New) The method of claim 69, wherein the control point is a first of a plurality of control points, and wherein the movement of at least the first control point and a second control point of the plurality of control points is operative to modify a slope associated with the first force profile.

73. (New) The method of claim 69, wherein the movement of the control point is operative to modify a damping parameter associated with the first force profile.

74. (New) The method of claim 69, wherein the control point is one of a plurality of control points, and wherein each control point from the plurality of control points is independently moveable.

75. (New) The method of claim 69, wherein the second force profile is symmetrical about a midpoint independent of the movement of the control point.

76. (New) A processor-readable medium comprising code representing instructions to cause a processor to:

output a signal associated with a first haptic force associated with a first force profile, the first force profile being associated with a graphical representation for display within a graphical

user interface, the graphical representation being illustrative of a force versus any one of a position, velocity or acceleration characteristic of the first force profile;

receive a control signal associated with a movement by a user of a control point of the graphical representation, the movement of the control point operative to change the first force profile to a second force profile; and

output a signal associated with a second haptic force, the second haptic force being based on the second force profile and being different from the first haptic force.

77. (New) An apparatus, comprising:

means for outputting a signal associated with a first haptic force associated with a first force profile, the first force profile being associated with a graphical representation for display within a graphical user interface, the graphical representation being illustrative of a force versus any one of a position, velocity or acceleration characteristic of the first force profile;

means for receiving a control signal associated with a movement by a user of a control point of the graphical representation, the movement of the control point operative to change the first force profile to a second force profile; and

means for outputting a signal associated with a second haptic force, the second haptic force being based on the second force profile and being different from the first haptic force.

78. (New) A method, comprising:

retrieving a first force profile associated with a first haptic force, the first force profile being associated with a graphical representation for display within a graphical user interface, the graphical representation being illustrative of a force versus any one of a position, velocity or acceleration characteristic of the first force profile;

receiving a control signal associated with a movement by a user of a control point of the graphical representation, the movement of the control point operative to change the first force profile to a second force profile; and

storing the second force profile associated with a second haptic force, the second haptic force being based on the second force profile and being different from the first haptic force.

79. (New) The method of claim 78, wherein at least one actuator is configured to output one of either the first haptic force or the second haptic force as a function of displacement of a manipulandum.

80. (New) The method of claim 78, wherein the movement of the control point is operative to modify a stiffness associated with the first force profile to obtain the second force profile.

81. (New) The method of claim 78, wherein the control point being a first control point from a plurality of control points, wherein the movement of at least the first control point and a second control point from the plurality of control points being operative to modify a slope associated with the first force profile.

82. (New) The method of claim 78, wherein the movement of the control point is operative to modify a damping parameter associated with the first force profile.

83. (New) The method of claim 78, wherein the control point is one of a plurality of control points, and wherein each control point from the plurality of control points is independently moveable.

84. (New) The method of claim 78, wherein the second force profile is symmetrical about a midpoint independent of the movement of the control point.

85. (New) A processor-readable medium comprising code representing instructions to cause a processor to:

retrieve a first force profile associated with a first haptic force, the first force profile being associated with a graphical representation for display within a graphical user interface, the graphical representation being illustrative of a force versus any one of a position, velocity or acceleration characteristic of the first force profile;

receive a control signal associated with a movement by a user of a control point of the graphical representation, the movement of the control point operative to change the first force profile to a second force profile; and

store the second force profile associated with a second haptic force, the second haptic force being based on the second force profile and being different from the first haptic force.

86. (New) An apparatus, comprising:

means for retrieving a first force profile associated with a first haptic force, the first force profile being associated with a graphical representation for display within a graphical user interface, the graphical representation being illustrative of a force versus a position, velocity or acceleration characteristic of the first force profile;

means for receiving a control signal associated with a movement by a user of a control point of the graphical representation, the movement of the control point operative to change the first force profile to a second force profile; and

means for storing the second force profile associated with a second haptic force, the second haptic force being based on the second force profile and being different from the first haptic force.